SHUAI ZHOU

Senior Undergraduate Student of Robotics

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EDUCATION

SOUTH CHINA UNIVERSITY OF TECHNOLOGY   **Guangzhou, China**
Bachelor of Engineering in Robotics; GPA: 3.86/4.00   *Sep 2022 — Jun 2026*

UNIVERSITY OF CALIFORNIA, BERKELEY   **Berkeley, USA**
Exchange Student concentrating in EECS; GPA: 4.00/4.00   *Aug 2023 — Dec 2023*

PUBLICATION(† equal contribution)

PREPRINT

[1] **Bridging Planning and Execution: Multi-Agent Path Finding Under Real World Deadlines**
Jingtian Yan†, **Shuai Zhou†**, Stephen Smith, Jiaoyang Li.
TRO (Under Review), 2026. [Paper]

PUBLISHED

[2] **LSRP*: Scalable and Anytime Planning for Multi-Agent Path Finding with Asynchronous Actions**
Shuai Zhou, Shizhe Zhao, Zhongqiang Ren.
SoCS, 2025. [Paper] [Web]
[3] **Loosely Synchronized Rule-Based Planning for Multi-Agent Path Finding with Asynchronous Actions**
Shuai Zhou, Shizhe Zhao, Zhongqiang Ren.
AAAI, 2025. [Paper] [Code] [Web]

SKILLS

Professional Services: Program Chair Member/Reviewer (IROS 2025)

Platforms: Unitree G1 Humanoid, Unitree Go1 Quadruped, UFACTORY X-ARM 7, Vicon

Simulators: Isaacsim, MuJoCo, PyBullet

Programming: Python, C++, Java, HTML, MATLAB, LaTeX

RESEARCH EXPERIENCE

CARNEGIE MELLON UNIVERSITY, SAFE AI Lab   **Pittsburgh, USA**
Supervisor: Prof. Ding Zhao   *Aug 2025 — Present*

- **Research Topics**: Manipulation, Cross-embodiment, Whole-body Controller.
- Learning versatile humanoid manipulation policy and developing robust lower-body controller.
- Egocentric cross-embodiment learning for versatile manipulation, experimenting with co-training/pretraining-finetuning policy on multiple embodiments (G1 Humanoid, Go1 Quadruped, and X-ARM 7).
- Collaborating with Stanford to collect a comprehensive physical robot dataset for tool use.

CARNEGIE MELLON UNIVERSITY, ARCS Lab   **Pittsburgh, USA**
Supervisor: Prof. Jiaoyang Li   *Apr 2025 — Present*

- **Research Topics**: Learning for Planning, Heuristic Search, Multi-Robot System.
- Learning execution-time prediction models for closed-loop multi-robot coordination and dependency optimization [1].
- Collaborative multi-robot non-prehensile manipulation via flow-matching model and lazy planning.

SHANGHAI JIAO TONG UNIVERSITY RAP Lab   **Shanghai, China**
Supervisor: Prof. Zhongqiang Ren   *Apr 2024 — Apr 2025*

- **Research Topics**: Heuristic Search, Multi-Robot System.
- Developed scalable planners for Multi-Robot Path Planning that scale to 1,000+ robots [3].
- Designed complete, anytime planning framework with pruning and sorting strategies that accelerated search [2].